

In the Claims:

Please amend the claims as follows:

1. (currently amended) A robot wrist with a plurality of rotatable parts arranged in series with each other, comprising:

~~at least~~ a first wrist part arranged in use to be mounted to a robot arm or automation machine to enable rotary movement of the first wrist part about a first axis,

a second wrist part journaled in the first wrist part,

wherein each wrist part ~~is arranged with one or more gear members~~ comprises at least one gear member configured to drive ~~a said~~ said rotary movement of any of said wrist ~~part~~ parts relative to ~~said~~ another of said wrist ~~part~~ parts, said at least one gear member having a conical surface, and

wherein a concave bevel gear arranged at a generatrix of the conical surface of least one of said gear members, ~~said concave bevel gear having~~ has a negative bevel angle relative to a plane perpendicular to ~~the rotation axis~~ an axis of rotation of said gear member.

2. (currently amended) The robot wrist according to claim 1, wherein at least one of said gear members ~~is arranged with a convex bevel gear with~~ has a positive bevel angle relative to a plane perpendicular to the rotation axis and at least one other said gear member ~~is arranged as~~ has a concave bevel gear with a negative bevel angle.

3. (previously amended) The robot wrist according to claim 1, wherein the negative

bevel angle lies in the range between 0 and - 20 degrees.

4. (currently amended) The robot wrist according to claim 1, wherein the negative bevel angle ~~(Cn)~~ lies in the range between -8 and -12 degrees.

5. (currently amended) The robot wrist according to claim 1, wherein ~~the~~ each gear member is an annular bevel gear.

6. (currently amended) The robot wrist according to claim 1, wherein said second wrist part ~~is arranged with~~ comprises a ~~said~~ bevel gear member with the negative bevel angle.

7. (currently amended) The robot wrist according to ~~claim 4,~~ claim 6, wherein the negative bevel angle of the gear member of said second wrist part is arranged to engage a gear member of said first wrist part.

8. (previously amended) The robot wrist according to claim 1, wherein each of said gear members has a hollow opening through which an inner protection hose is arranged.

9. (previously amended) The robot wrist according to claim 8, wherein the inner protection hose is arranged so as to pass through the inside of the wrist parts arranged in a single circular arc when the wrist is in a bent position.

10. (currently amended) The robot wrist according to claim 8, wherein a longitudinal

axis the inner protection hose passing through the inside of the wrist parts has ~~the~~ a same total length when arranged in each of a bent and a straight position.

11. (currently amended) The robot wrist according to claim 8, wherein the inner protection hose ~~is a hose with~~ has a substantially cylindrical wall.

12. (currently amended) The robot wrist according to claim 11, wherein the inner protection hose ~~is a hose with~~ has a cylindrical wall that has a straight and parallel wall cross-section.

13. (currently amended) The robot wrist according to claim 12, wherein the inner protection hose ~~is a hose with~~ has a wall cross-section in the form of a wave.

14. (previously amended) The robot wrist according to claim 12, wherein the inner protection hose comprises an articulated hose comprising circular sections of at least two different diameters.

15. (currently amended) The robot wrist according to claim 13, wherein the inner protection hose ~~is formed of~~ comprises a polymeric material combined with at least one metal reinforcing member.

16. (previously amended) The robot wrist according to claim 15, wherein the inner protection hose comprises a fluoropolymer.

17. (previously amended) The robot wrist according to claim 15, wherein the metal reinforcing member comprises a plurality of metal rings.

18. (previously amended) The robot wrist according to claim 13, wherein the metal reinforcing member comprises any of a spiral wire or a helical wire.

19. (previously amended) The robot wrist according to claim 18, wherein the metal rings, spiral wire or helical wire of the hose are attached to the outside surface of the polymeric material.

20. (previously amended) The robot wrist according to claim 18, wherein the rings, spiral wire or helical wire of the hose are embedded in the polymeric material.

21. (previously amended) The robot wrist according to claim 1, wherein a plurality of hoses and/or cables are arranged inside said inner protection hose inside the wrist parts.

22. (previously amended) The robot wrist according to claim 21, wherein the plurality of hoses and/or cables are twisted to a predetermined extent inside the inner protection hose and comprise any from the list of: hose, wire, feed rod, cable.

23. (previously amended) The robot wrist according to claim 22, wherein the plurality of hoses and/or cables are arranged installed inside the robot wrist twisted to a predetermined

extent through 180 degrees.

24. (currently amended) The robot wrist according to claim 1, wherein the negative bevel angle of the gear member of said second wrist part is arranged facing a third wrist part.

25. (previously amended) The robot wrist according to claim 24, wherein the third wrist part is journaled in the second wrist part to enable rotary movement of the third wrist part relative the second wrist and the second wrist part relative the first.

26. (currently amended) The robot wrist according to ~~claim 1~~, claim 25, wherein a gear member of the first wrist part is arranged to engage a gear member of the second wrist part such that the second wrist part ~~transfers effect to~~ rotatably drives ~~drive~~ a gear member of the third wrist part engaged by a second gear member of the second wrist part.

27. (currently amended) The robot wrist according to claim 26, wherein the second part gear members ~~transferring effect to~~ rotatably driving the third part gear member are arranged in the second part such that their axes of rotation are at an inclined angle to each other.

28. (previously amended) The robot wrist according to claim 26, wherein a first part gear member and a third part gear member are convex bevel gears with a positive gear angle and a second part gear member is a concave bevel gear with a negative bevel angle.

29. (currently amended) The Use of a robot wrist according to claim 1, further

comprising: for

an internal or an external surface treatment ~~operation~~ or painting ~~operation with an industrial robot~~ tool.

30. (currently amended) The Use of a robot wrist according to claim 1, further
comprising: for

a welding operation ~~with an industrial robot~~ tool.

31. (currently amended) The Use of a robot wrist according to claim 1, further
comprising: for

a picking and/or packing ~~operation with an industrial robot~~ tool.

32. (currently amended) The Use of a robot wrist according to claim 1, further
comprising: for

a machine tending ~~operation with an industrial robot~~ tool.